

Patent claims

1. Method for determining an actual position (A) of a
5 geodetic instrument (1, 1'),

comprising a positioning system which is based on
the reception of shadowable signals,

10 and a dead range (T, T') within which the
propagation of the signal is impaired in such a
way that a direct determination of the actual
position (A) by means of the positioning system is
at least limited,
15 comprising the steps
- recording of a first piece of image information
from a first known position (P1) determined in
20 particular by means of the positioning system,
the first piece of image information having at
least two identifiable reference structures (5,
5', 5'') which can be detected at least from a
partial region of the dead range (T, T'), and
25 measurement of at least one first distance from
the first known position (P1), the first
distance being coordinated indirectly or
directly with the reference structures (5, 5',
5''),
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 - recording of a second piece of image
information from a second known position (P2)
determined in particular by means of the

positioning system, the second piece of image information having at least the two identifiable reference structures (5, 5', 5''), and measurement of at least one second distance from the second known position (P2), the second distance being coordinated indirectly or directly with the reference structures (5, 5', 5'')

10 - recording of a piece of actual image information from an actual position (A), the actual image information having at least the two identifiable reference structures (5, 5', 5''), and measurement of at least one actual distance from the actual position (A), the actual distance being coordinated indirectly or directly with the reference structures (5, 5', 5''),

20 - derivation of the actual position (A) by referencing relative to the at least two reference structures (5, 5', 5''),

it being possible for individual steps or a plurality of the steps to be repeated.

2. Method according to Claim 1, characterized in that one distance is measured in each case in the measurement of the distances to each of the reference points (5, 5', 5'').

3. Method according to Claim 1 or 2, characterized in that a measurement of the distance to each point

of a detected image is effected in the recording of the image information.

4. Method according to Claim 1, 2 or 3, characterized in that the position of the two reference structures (5, 5', 5'') is determined in the derivation of the actual position (A).
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5. Method according to Claim 4, characterized in that the derivation of the actual position (A) is effected by means of a trilinear surveying method.
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6. Method according to Claim 1, 2 or 3, characterized in that, in the derivation of the actual position (A), a transformation is used which links the actual position (A) via the at least two reference structures (5) to the first known position (P1) and the second known position (P2).
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7. Method according to any of the preceding Claims, characterized in that the measurement of the distances is carried out by means of optical distance measurement, in particular laser distance measurement.
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8. Method according to any of the preceding Claims, characterized in that the positioning system is the Global Positioning System or another satellite-supported system.
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9. Method according to any of Claims 1 to 8, characterized in that the positioning system is an Earth-supported system, in particular a Total
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Positioning System.

10. Method according to any of the preceding Claims,
characterized in that the at least two reference
5 structures (5, 5', 5'') are tracked and/or
identified automatically.
11. Method according to any of the preceding Claims,
characterized in that at least the first piece of
10 image information is stored and the at least two
reference structures (5, 5', 5'') in the second
piece of image information and/or the actual image
information are identified by image processing
methods, in particular by matching methods.
12. Method according to any of the preceding Claims,
characterized in that the recording of the first
and second pieces of image information and the
measurement of the first and second distances are
15 carried out in an automated manner, in particular
are constantly repeated.
13. Method according to Claim 12, characterized in
that, in the event of a limitation of the direct
25 determination of the actual position (A) by means
of the positioning system, the derivation of the
actual position (A) is effected in an automated
manner, in particular repeatedly or continuously.
14. Device for determining an actual position (A) of a
30 geodetic instrument (1) by a method according to
any of Claims 1 to 13, comprising the components

- image recording unit (10), in particular having an image memory and/or an image information memory (13),
- telemeter (12), in particular laser telemeter,
- data processing unit (14) for deriving the actual position,

characterized in that

the components are formed and arranged in such a way that a method according to any of Claims 1 to 13 can be carried out in an automated manner.

15. Device according to Claim 14, characterized in that the telemeter is integrated in the image recording unit (10), in particular in the form of a range imaging sensor or of a scanning telemeter.

16. Device according to Claim 14 or 15, characterized in that the data processing unit (14) is formed in such a way that a limitation of the direct determination of the actual position (A) by means of the positioning system is recognisable and an alarm and/or an automated derivation of the actual position (A) can be triggered.

17. Device according to Claim 14, 15 or 16, characterized by an inclinometer (15).

18. Device according to any of Claims 14 to 17, characterized by a direction meter (16), in particular a magnetic compass.

19. Geodetic instrument (1) comprising a unit for position determination by means of a positioning system based on the reception of shadowable signals, in particular comprising a unit for position determination which has a reflector for geodetic surveying or a GPS receiver (8), and a device according to any of Claims 14 to 18.
20. Computer program as a record on a data medium or in the form of a data signal for carrying out the method according to any of Claims 1 to 13.